



"stewart platform" spring

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**[PS] The Stewart platform manipulator: a review**

B Dasgupta, TS Mruthyunjaya - Mechanism and Machine Theory, 2000 - iitk.ac.in  
 ... Kerr [82] analysed a similar structure and enumerated a few design criteria for the sensor structure. The concept of a passive **Stewart platform** with **spring**- ...  
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**[PS] Design and control of a simplified Stewart platform for endoscopy**

J Wendlandt, SS Sastry - Proc. IEEE Conf. Decision Contr, 1994 - robotics.eecs.berkeley.edu  
 ... useful for applications which do not need the full motion of the **Stewart platform**. ...  
 consists of two platforms separated by rigid tubes and a **spring**-like device ...  
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**Modeling, simulation, and control of a hydraulic stewart platform**

D Li, SE Salcudean - Proc. IEEE int. Conf. Robotics and Automat, 1997 - ieeexplore.ieee.org  
 ... For the **Stewart platform** considered here, the mass of the six legs is considerably ...  
 coefficient (normally piston seal friction), K is the **spring** constant of ...  
 Cited by 10 - [Web Search](#) - [ece.ubc.ca](#) - [ee.ubc.ca](#) - [ieeexplore.ieee.org](#)

**A six-component contact force measurement device based on the Stewart platform**

JS Dai, DR Kerr - Proceedings of the Institution of Mechanical Engineers. Pt. ..., 2000 - ex.ac.uk  
 ... based on the **Stewart platform** ... The geometry of the device is based upon that  
 of the **Stewart platform** manipulator, configured symmetrically. ...  
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**Implementation of Stewart Platform Based Force-Torque Sensor**

TA Dwarakanath, TK Bhaumick, D Venkatesh - Multisensor Fusion and Integration for Intelligent Systems, ..., 1999 - ieeexplore.ieee.org  
 ... The concept of a passive **Stewart platform** with **spring** loaded legs was used by Griffis  
 and Duffy [7] for theoretical modeling of a compliant coupling. ...  
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**Real Time Control of the MIT Vehicle Emulator System**

WK Durfee, HR Idris, S Dubowsky - robots.mit.edu  
 ... six DOF, but is coupled to the ground through six independent **spring**-damper suspension ...  
 a set of six desired leg lengths based on the **Stewart platform** geometry. ...  
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**Modeling and Simulation of Robotic Systems with Closed Kinematic Chains Using the Virtual Spring**

J Wang, CM Gosselin, L Cheng - Multibody System Dynamics, 2002 - kluweronline.com  
 ... or mechanical systems with closed kinematic chains using the virtual **spring** approach  
 is ... links as well as the six-degree-of-freedom Gough-**Stewart platform**. ...  
 Cited by 3 - [Web Search](#) - [springerlink.com](#)

**On the use of Virtual Springs to avoid Singularities and Workspace Boundaries in Force-Feedback**

A Rubio, A Avello, J Florez, SS CEIT - Robotics and Automation, 2000. Proceedings. ICRA'00. IEEE ..., 2000 - ieeexplore.ieee.org  
 ... implemented in a force-feedback teleoperator composed of a **Stewart platform** as master ...  
 For instance, if the desired master impedance includes a **spring** (MS2+Ds ...  
 Cited by 4 - [Web Search](#) - [ieeexplore.ieee.org](#) - [csa.com](#)

Analysis and implementation of a 6 DOF Stewart platform-based force sensor for passive compliant ...

CC Nguyen, SS Antrazi, ZL Zhou - Southeastcon'91., IEEE Proceedings of, 1991 - [ieeexplore.ieee.org](http://ieeexplore.ieee.org)  
... to the end-effector platform are computed by using the inverse and forward kinematic transformations of the **Stewart platform**, the known **spring** constants, and ...  
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On the stiffness and stability of Gough-Stewart platforms

MM Svinin, S Hosoe, M Uchiyama - PROC IEEE INT CONF ROB AUTOM, 2001 - [ieeexplore.ieee.org](http://ieeexplore.ieee.org)  
... Pigoski et al. (1992) used a planar, three **spring**, elastic coupling ... an asymmetric stiffness matrix for a **Stewart platform**- type mechanism with six springs. ...  
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